

REMARKS/ARGUMENTS

A substitute specification is being filed in order to conform with U.S. practice. Headings have been added to the specification. Spelling and grammatical errors have also been corrected. The substitute specification contains no new matter. Amendments have been made to the claims to remove the multiple dependencies and an abstract has been added. An early action on the merits is respectfully requested.

If any additional fees are required in connection with this case, it is respectfully requested that they be charged to Deposit Account No. 02-0184.

Respectfully submitted,

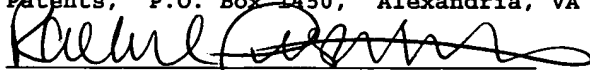
Jorge Henle

By

Gregory P. LaPointe  
Attorney for Applicants  
Reg. No. 28,395  
Tel: (203) 777-6628  
Fax: (203) 865-0297

Date: August 4, 2005

I hereby certify that this correspondence is being deposited with the United States Postal Service as Express Mail in an envelope addressed to: "Commissioner for Patents, P.O. Box 1450, Alexandria, VA 22313" on August 4, 2005.

  
Rachel Piscitelli

SUBSTITUTE SPECIFICATION WITH MARKINGS

## Device for controlling a vehicle

BACKGROUND OF THE INVENTION

[0001] The present invention relates to an apparatus for controlling a vehicle, in particular an aircraft, helicopter or else a simulator, having a handle which is mounted such that it can move about two approximately mutually perpendicular axes.

[0002] Apparatuses such as these are known and are commercially available on the market in many forms and versions. They are essentially used for controlling aircraft, helicopters, flight simulators or the like. In this case, a handle can be pivoted essentially about two axes in order, for example, to control a helicopter, in particular its rotor.

[0003] Conventional apparatuses have the disadvantage that they are large, complex and costly, in particular with different linkages. In this case, complicated levers and deflection systems are required in order to produce two different movable axes for helicopter control, in order, for example, to drive the rotor. Procurement of these apparatuses is thus expensive, and they are costly to maintain.

[0004] US 4,422,345 discloses a control lever, which can be mechanically pivoted about two axes arranged on different planes.

[0005] US 6,057,828 discloses an apparatus for determination of forces in virtual environments of any desired tools, in which case it is possible to determine a force of any desired tool or handle or action.

[0006] US 4,555,960 discloses a joystick with six degrees of freedom, with the handle itself once again detecting two additional movements, via appropriate cross-linkages.

[0007] Patent Abstracts of Japan, Vol. 1997, No. 07 July 31, 1997 and JP 09 062392 A discloses a monitoring device in which a force sensor for determination of the load applied to the handle is arranged for this purpose between the handle and a corresponding holder. In this case, the handle is connected to a baseplate via two plates which are hinged with respect to one another, and can be moved on only one plane.

[0008] The present invention is based on the object of providing an apparatus of the type mentioned initially, which overcomes the stated disadvantages and by means of which an apparatus for exact control of vehicles, aircraft, helicopters and simulators is possible in a simple and cost-effective manner, and which also allows active force feedback to the handle. In this case, the aim is to allow this apparatus to be accommodated well in confined installation spaces. A further aim is to improve the safety during operation.

#### SUMMARY OF THE INVENTION

[0009] ~~The features of patent claim 1 lead to the achievement of this object.~~ The foregoing objects are achieved by the present invention by providing an apparatus for controlling a vehicle, in particular an aircraft, helicopter or else a simulator, having a handle which is mounted such that it can move about two approximately mutually perpendicular axes (A, B),

characterized in that the axes (A, B) are located on different planes ( $E_1$  and  $E_2$  or  $E_1$  and  $E_3$ ) and are offset with respect to one another.

[0010] In the case of the present invention, it is important that an apparatus is provided which is formed from a frame element with adjacent baseplates on each side. A baseplate is connected to a drive element, which is fitted with a force sensor, via a holding element, such that it can pivot about a first axis and allows a pivoting movement about this first axis, possibly by means of force feedback.

[0011] In order to move the handle about a further axis at right angles to this, a further drive element is connected to a baseplate of the frame element, and is preferably firmly connected to the structure of the vehicle, helicopter or simulator.

[0012] In one preferred exemplary embodiment, the two axes which are at right angles to one another are on different parallel planes, and are offset with respect to one another.

[0013] This ensures that different movement options and pivoting mechanisms of the handle are provided, which is particularly important for actuation of helicopter rotors.

[0014] In this case, one aim is to ensure that the one axis is offset upwards or downwards with respect to the other axis. This makes it possible to produce different pivoting movements about the first axis or about the second axis by pivoting the axes to different extents. In addition, a force acting on the handle can

be measured via the force sensor, and allows force feedback via the drive elements. This is likewise intended to be within the scope of the present invention.

#### BRIEF DESCRIPTION OF THE DRAWINGS

[0015] Further advantages, features and details of the invention will become evident from the following description of preferred exemplary embodiments, in which:

[0016] Figure 1 shows a perspective illustration of an apparatus according to the invention for controlling a vehicle, in particular an aircraft;

[0017] Figure 2a shows a perspective plan view of one preferred exemplary embodiment of the apparatus for controlling an aircraft as shown in Figure 1;

[0018] Figure 2b shows a perspective rear view of the apparatus as shown in Figure 2a;

[0019] Figure 3a shows a perspective plan view of yet another exemplary embodiment of the apparatus as shown in Figure 1; and

[0020] Figure 3b shows a schematically illustrated rear view of the apparatus as shown in Figure 3a.

#### DETAILED DESCRIPTION

[0021] As seen in Figure 1, an apparatus  $R_1$  according to the invention has a frame element 1 for controlling vehicles or simulators, in particular aircraft simulators, which frame element 1 is preferably formed from a baseplate 2 and holding plates 3.1, 3.2 which are adjacent on each side and are at right

angles to the baseplate 2.

[0022] A first drive element 5.1 is connected on the outside to the frame element 1, in particular to the holding plate 3.1, via an output flange 4. In this case, the drive element 5.1 lies on an axis A which is at right angles to the holding plate 3.1.

[0023] A further drive element 5.2 is connected on the outside to the baseplate 2 of the frame element and is firmly connected to a structure, a holder or the like of the simulator or vehicle, although this is not illustrated here.

[0024] The drive element 5.2 is arranged on an axis B which runs approximately at right angles to the baseplate 2. In this exemplary embodiment, the axes A and B intersect at an intersection point S on a common plane  $E_1$ .

[0025] The drive elements 5.1, 5.2 are essentially formed from an electronic control device 6 and an electric motor 7 which is connected to it and has a transmission 8 on the output side. In this case, the electronic control device 6 may contain force control, motor control, etc.

[0026] A balance weight 9 is connected to the holding plate 3.2, and its center of gravity is located on the axis A. The balance weight 9 is used for mass balancing of the drive element 5.1, which can be pivoted together with the frame element 1 about the axis B by means of the drive element 5.2.

[0027] A holding element 10 is connected to the drive element 5.1, adjacent to the output flange 4, and can be pivoted about the axis A by means of the drive element 5.1. The holding element

10 is preferably in the form of a bracket, to which a force sensor 11 is connected. This likewise allows the position of the force sensor to be influenced.

[0028] The force sensor 11, whose axis C runs at right angles through the intersection point S of the axes A and B, is used to hold a handle 12, which is actively controllable or is mounted such that it can be pivoted by means of the human hand about the axes A and B. In this case, the drive elements 5.1, 5.2 provide force feedback, for active control. The force sensor 11 can receive the appropriate resetting moments and can appropriately control them or compensate for them via the drive elements 5.1, 5.2.

[0029] In a further preferred exemplary embodiment of the present invention as shown in Figure 2a, Figure 2a shows an apparatus  $R_2$  which corresponds approximately to the apparatus mentioned above.

[0030] One significant difference in this case is that the drive element 5.2 and its axis B are offset by a distance  $\Delta X$  with respect to the axis A of the drive element 5.1. The axes A and B are at right angles to one another, but are offset with respect to one another by the distance  $\Delta X$  on different planes  $E_1$ ,  $E_2$ , which are parallel to one another.

[0031] This ensures that different movement capabilities of the handle 12, which is not illustrated here, about the axis A or B are possible.

[0032] The corresponding rear view once again shows the

corresponding movement of the axes A and B with respect to one another.

[0033] In this case, the axis B is located above the axis A, with the baseplate 1 of the frame element 1 overhanging the holding plates 3.1, 3.2 at the end in this area, preferably in a slightly curved manner.

[0034] In the exemplary embodiment of the present invention as shown in Figures 3a and 3b, Figures 3a and 3b show an apparatus  $R_3$  which corresponds approximately to the type described above.

[0035] The difference here is that the axis B is offset by the distance  $\Delta X$ , in the manner described above, below the axis A. In this case, the axes A and B are likewise at right angles to one another, and lie on different planes  $E_1$ ,  $E_2$  which are parallel to one another.

[0036] This likewise ensures that the handle 12, which is connected to the force sensor 11, carries out different movements about the axes A and B. This makes it possible to influence different installation spaces, if the axis A is located above the axis B, or vice versa.

[0037] It is also possible for the different axes A and B or rotation axes to additionally ensure that the height of the force sensor 11 and of the handle 12 can be adjusted.